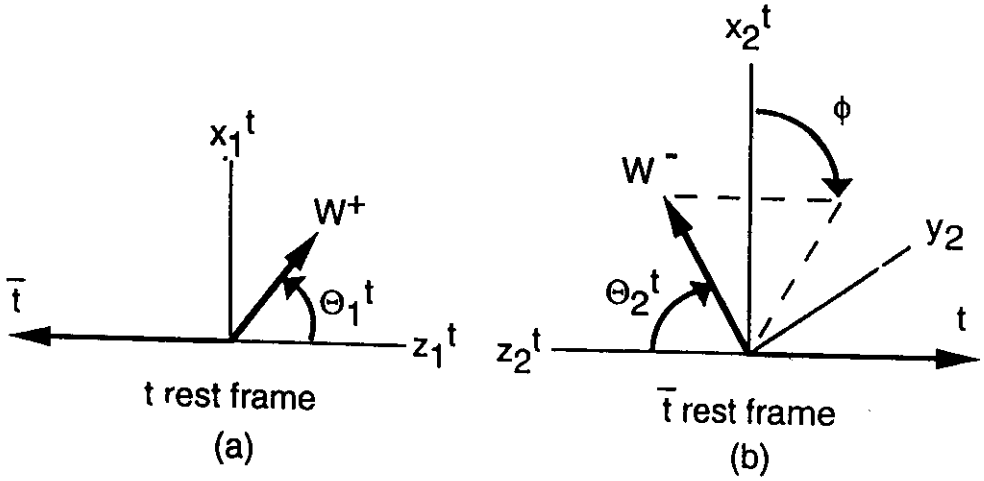
x_1^t
W^+
$\bar{t}$
Θ_1^t
z_1^t
t rest frame
(a)
x_2^t
ϕ
W^-
y_2
Θ_2^t
z_2^t
t
$\bar{t}$ rest frame
(b)

Fig. 1

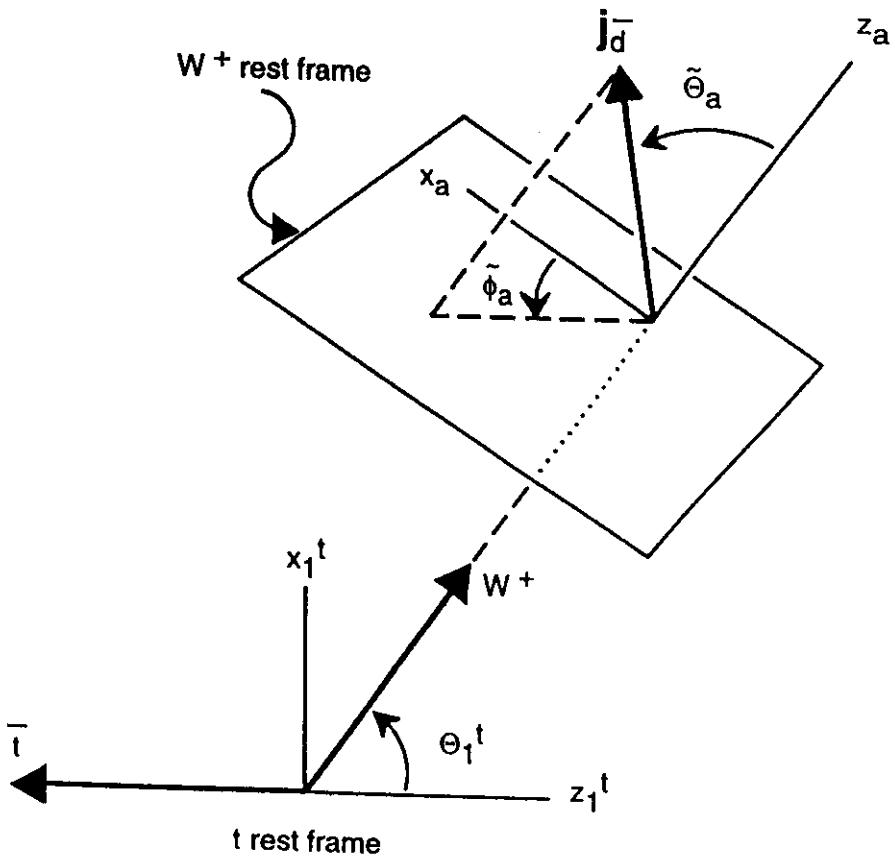
$j_{\bar{d}}$
z_a
W^+ rest frame
$\tilde{\Theta}_a$
x_a
$\tilde{\phi}_a$
x_1^t
W^+
$\bar{t}$
Θ_1^t
z_1^t
t rest frame

Fig. 2

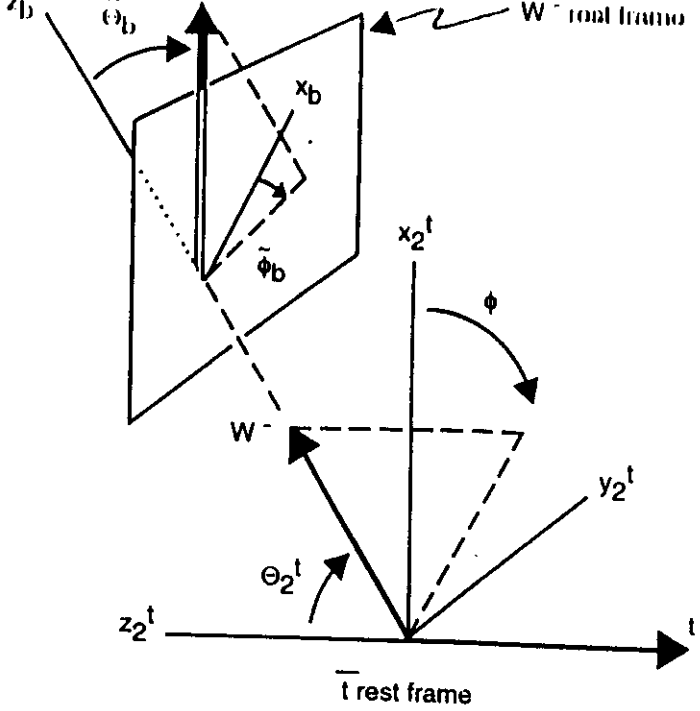
z_b
Θ_b
W - rest frame
x_b
$\tilde{\phi}_b$
x_2^t
ϕ
W -
y_2^t
Θ_2^t
z_2^t
t
$\bar{t}$ rest frame

Fig. 3

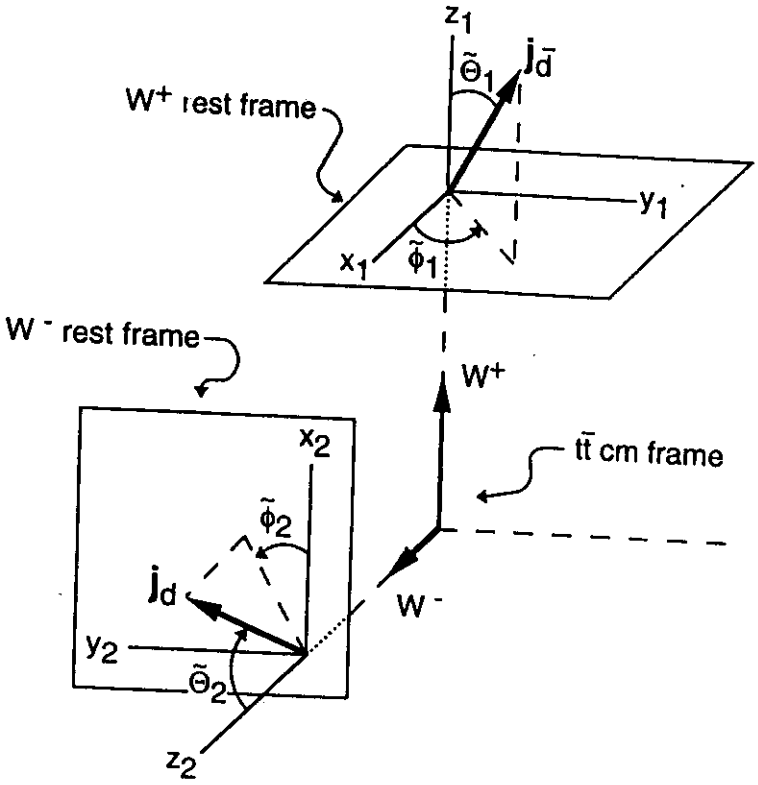
z_1
$\tilde{\Theta}_1$
$j_{\bar{d}}$
W+ rest frame
y_1
x_1
$\tilde{\phi}_1$
W - rest frame
W+
$t\bar{t}$ cm frame
x_2
$\tilde{\phi}_2$
j_d
W -
y_2
$\tilde{\Theta}_2$
z_2

Fig. 4

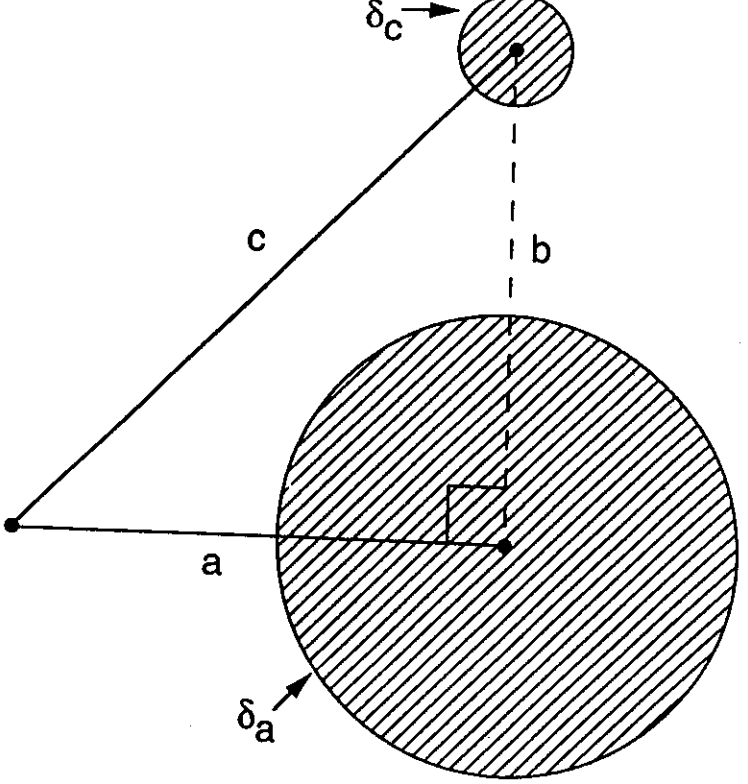

Fig. 5

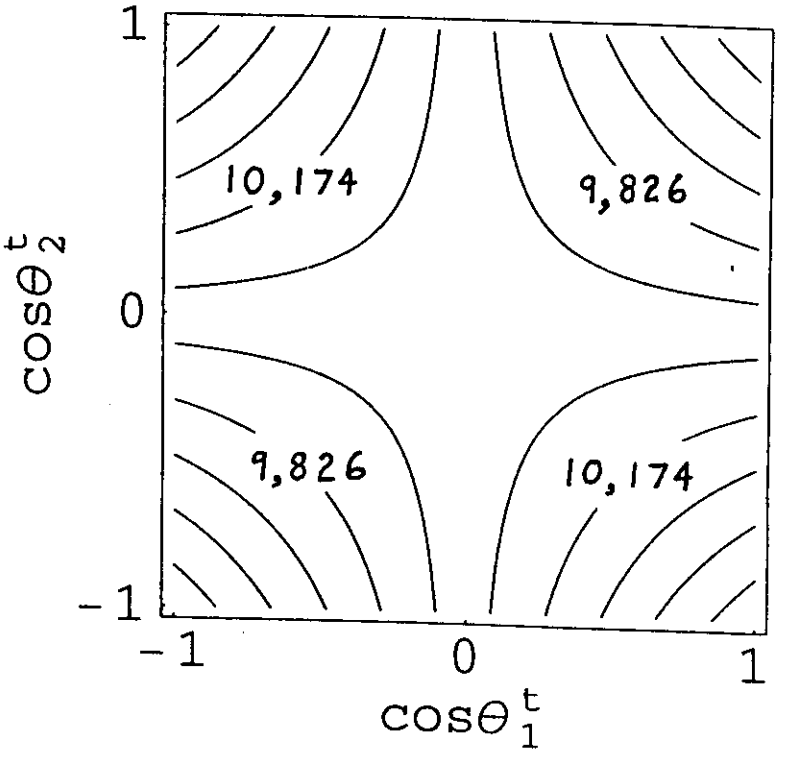

Fig. 6

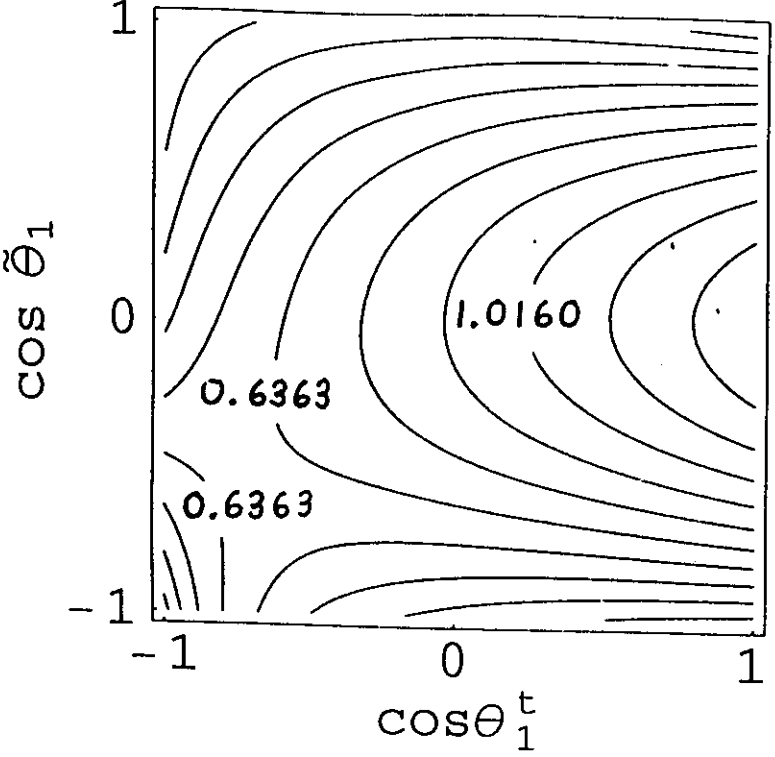
1
0
-1
cos $\tilde{\theta}_1$
1.0160
0.6363
0.6363
-1
0
1
cosθ_1^t

Fig. 7

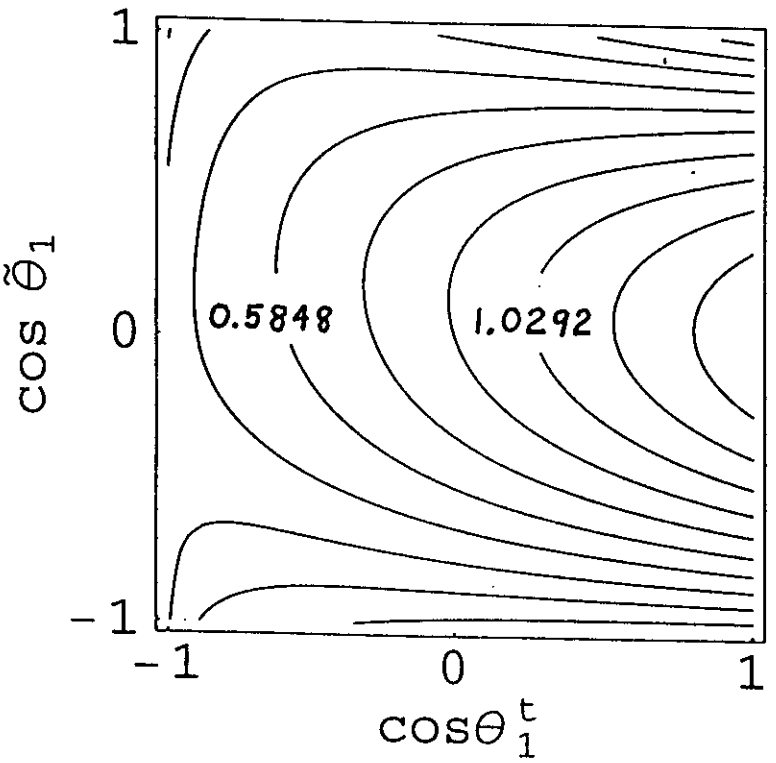
1
0
-1
cos $\tilde{\theta}_1$
0.5848
1.0292
-1
0
1
cosθ_1^t

Fig. 8

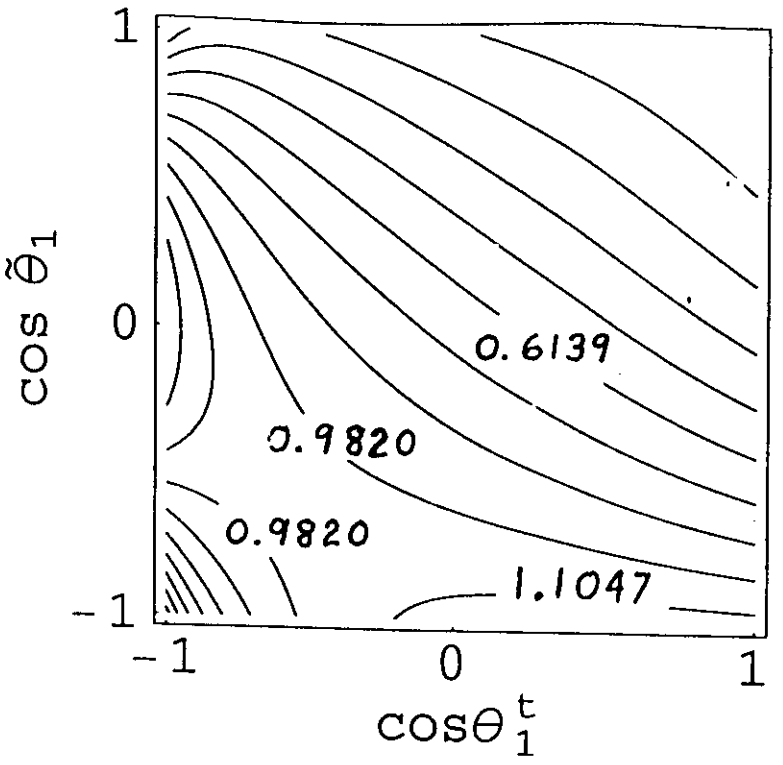
1
0
-1
-1
0
1
cos $\tilde{\Theta}_1$
cosΘ_1^t
0.6139
0.9820
0.9820
1.1047

Fig. 9

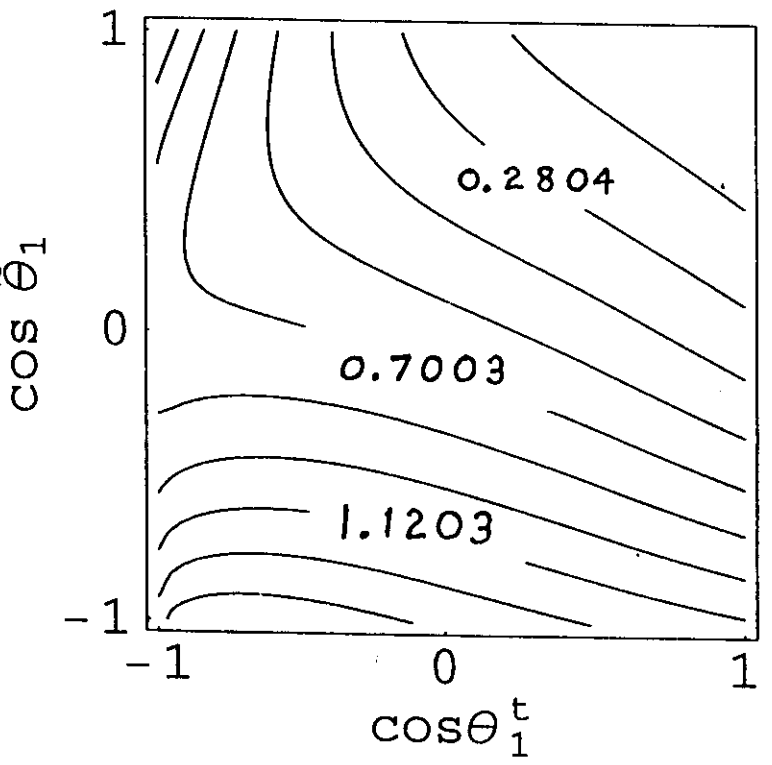
1
0
-1
-1
0
1
cos $\tilde{\Theta}_1$
cosΘ_1^t
0.2804
0.7003
1.1203

Fig. 10

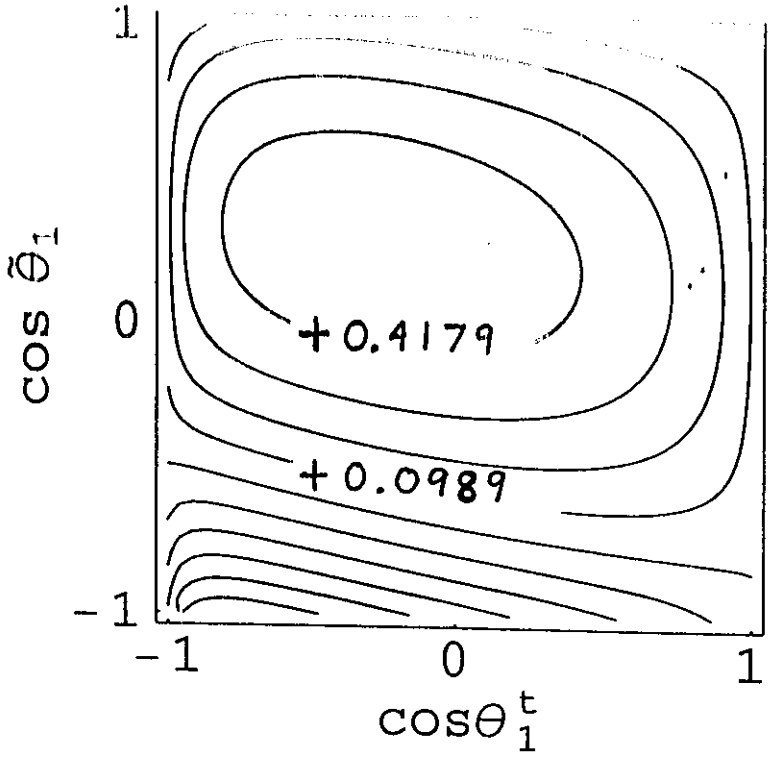
1
0
-1
cos $\tilde{\theta}_1$
+0.4179
+0.0989
-1
0
1
$\cos\theta_1^t$

Fig. 11

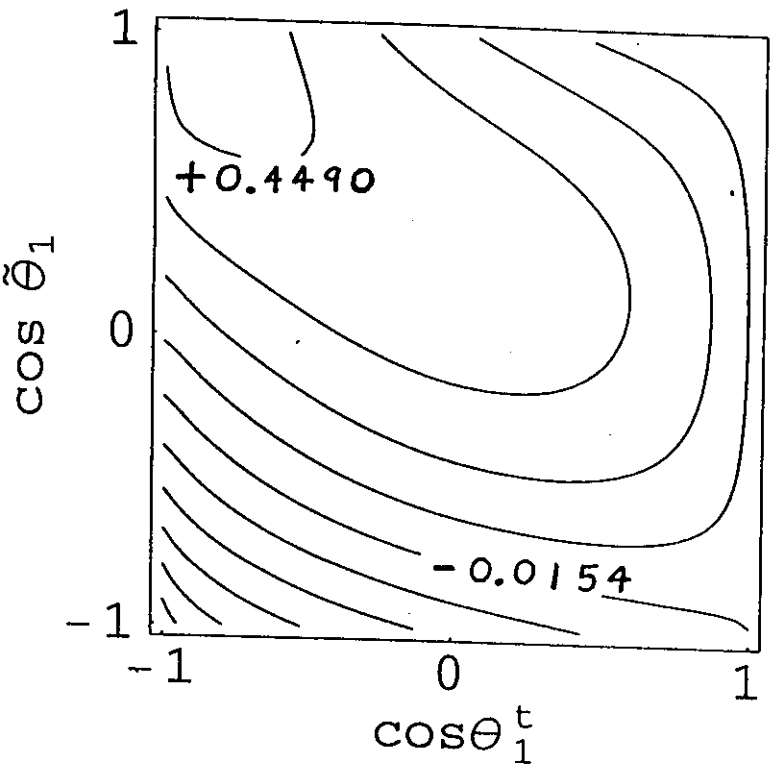
1
0
-1
cos $\tilde{\theta}_1$
+0.4490
-0.0154
-1
0
1
$\cos\theta_1^t$

Fig. 12

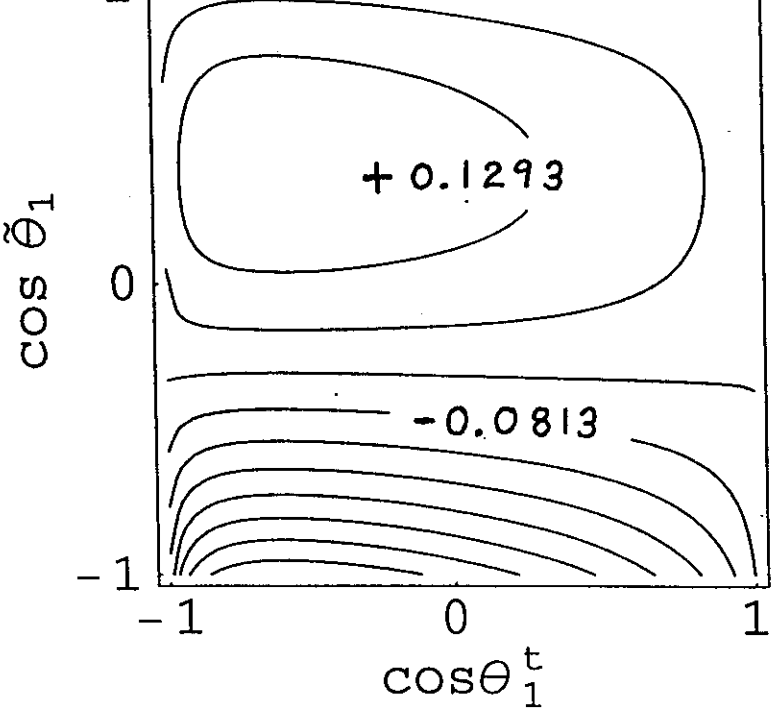
+0.1293
-0.0813
cos $\tilde{\theta}_1$
0
-1
-1
0
1
cosθ_1^t

Fig. 13

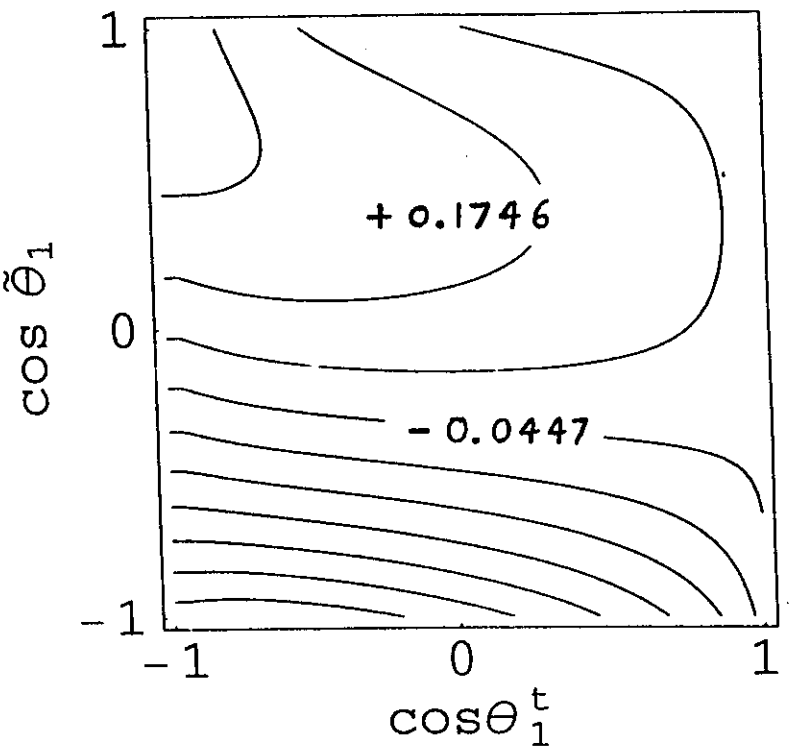
+0.1746
-0.0447
cos $\tilde{\theta}_1$
1
0
-1
-1
0
1
cosθ_1^t

Fig. 14